

(12) **United States Patent**  
**Horii et al.**

(10) **Patent No.:** **US 11,226,683 B2**  
(45) **Date of Patent:** **Jan. 18, 2022**

(54) **TRACKING STYLUS IN A VIRTUAL REALITY SYSTEM**

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(\*) Notice: Subject to any disclaimer, the term of this patent is extended or adjusted under 35 U.S.C. 154(b) by 0 days.

(21) Appl. No.: **16/606,480**

(22) PCT Filed: **Apr. 20, 2018**

(86) PCT No.: **PCT/US2018/028529**

§ 371 (c)(1),  
(2) Date: **Oct. 18, 2019**

(87) PCT Pub. No.: **WO2019/203848**

PCT Pub. Date: **Oct. 24, 2019**

(65) **Prior Publication Data**

US 2021/0333875 A1 Oct. 28, 2021

(51) **Int. Cl.**  
**G06F 3/01** (2006.01)  
**G06F 3/0354** (2013.01)  
**G06T 7/73** (2017.01)  
**G06F 3/03** (2006.01)  
**G06T 7/246** (2017.01)  
**G06F 3/0346** (2013.01)

(52) **U.S. Cl.**  
CPC ..... **G06F 3/014** (2013.01); **G06F 3/0304** (2013.01); **G06F 3/0346** (2013.01); **G06F 3/03546** (2013.01); **G06T 7/248** (2017.01); **G06T 7/74** (2017.01)

(58) **Field of Classification Search**  
CPC ..... **G06F 3/014**; **G06F 3/0304**; **G06F 3/0346**; **G06F 3/03546**; **G06T 7/74**; **G06T 7/248**  
See application file for complete search history.

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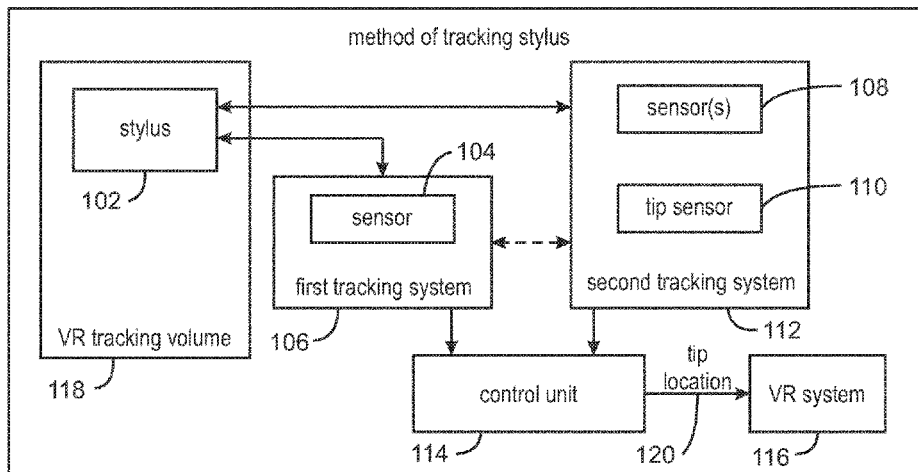
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(57) **ABSTRACT**

An apparatus is disclosed to monitor movement of a held object in a virtual reality system. The apparatus comprises a primary tracking system with a first sensor to monitor movement of the user's hand, and a secondary tracking system with a second sensor to monitor a position of the held object. The position is measured in relation to the hand movement.

**14 Claims, 11 Drawing Sheets**



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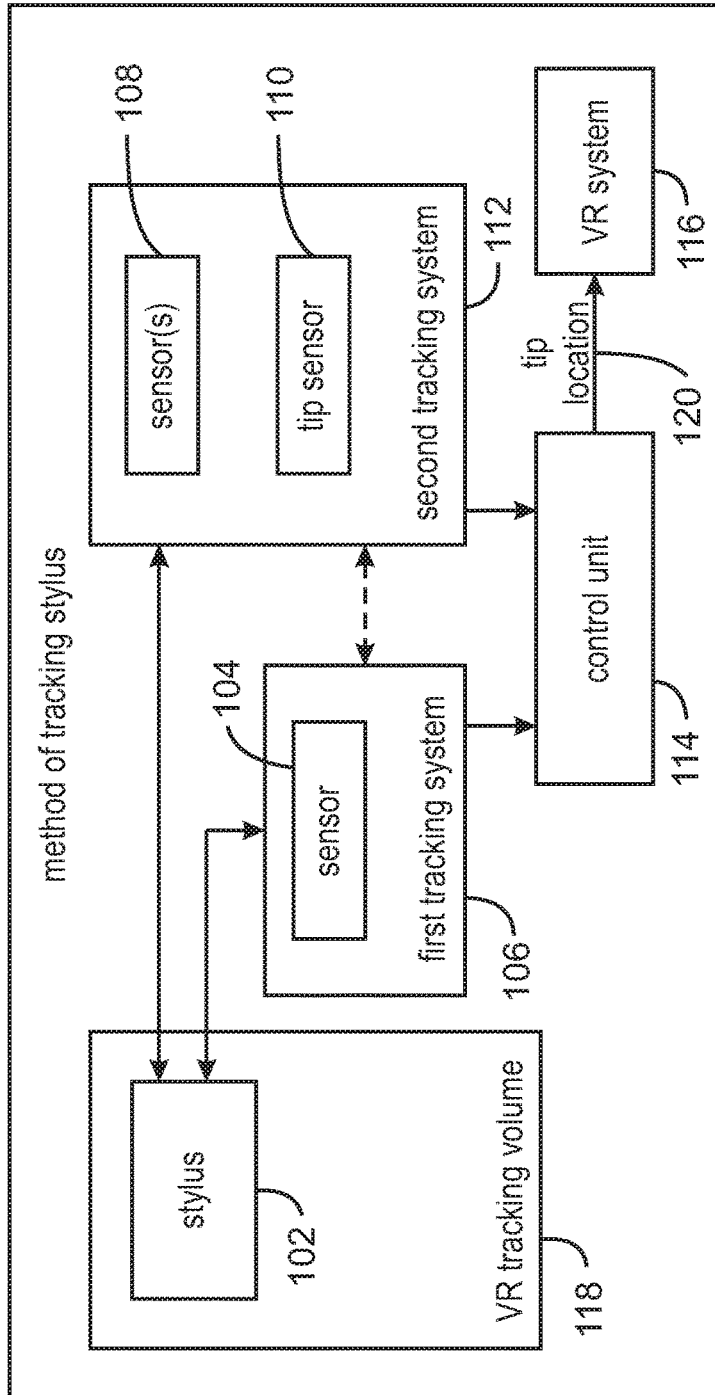
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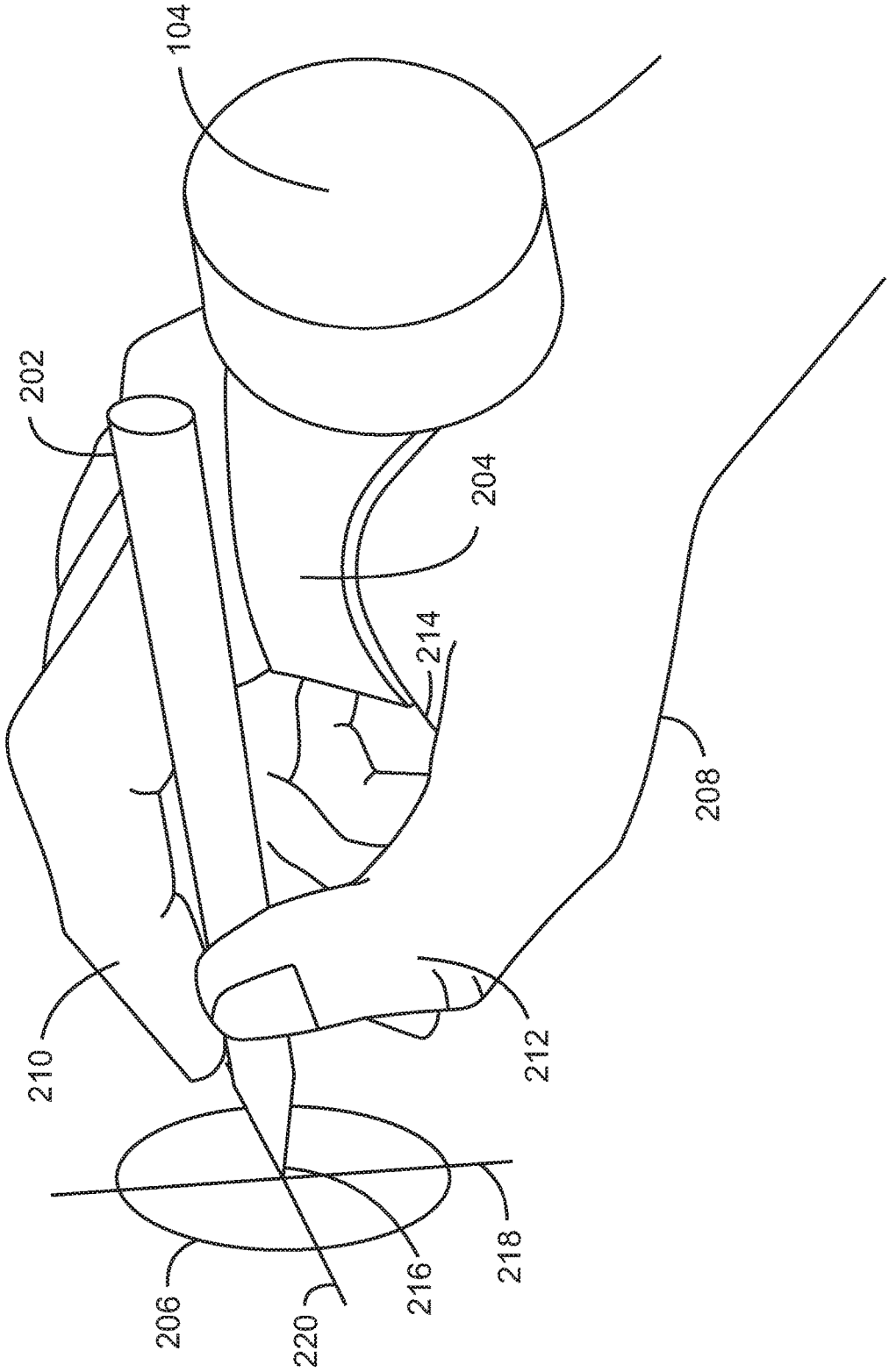
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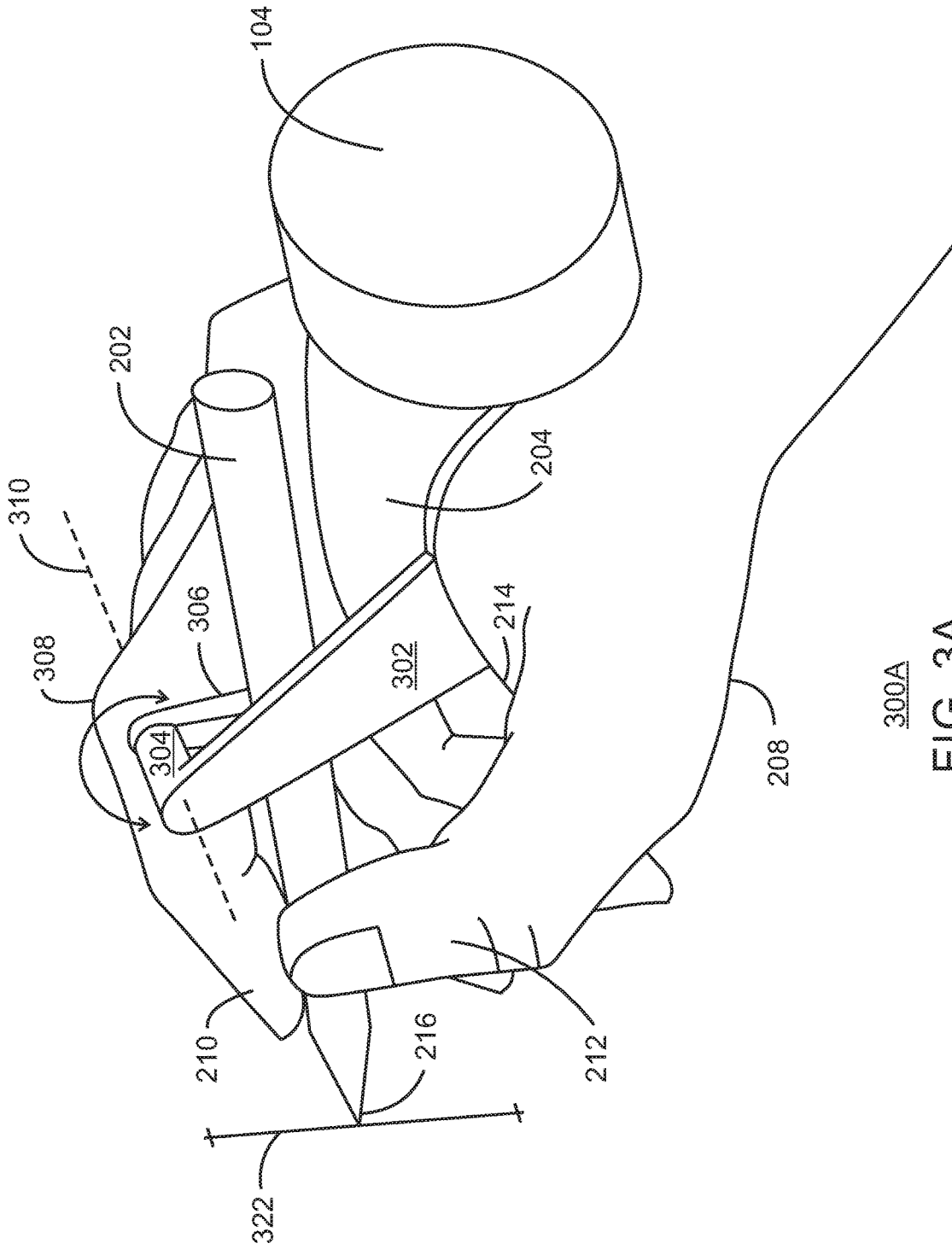


100

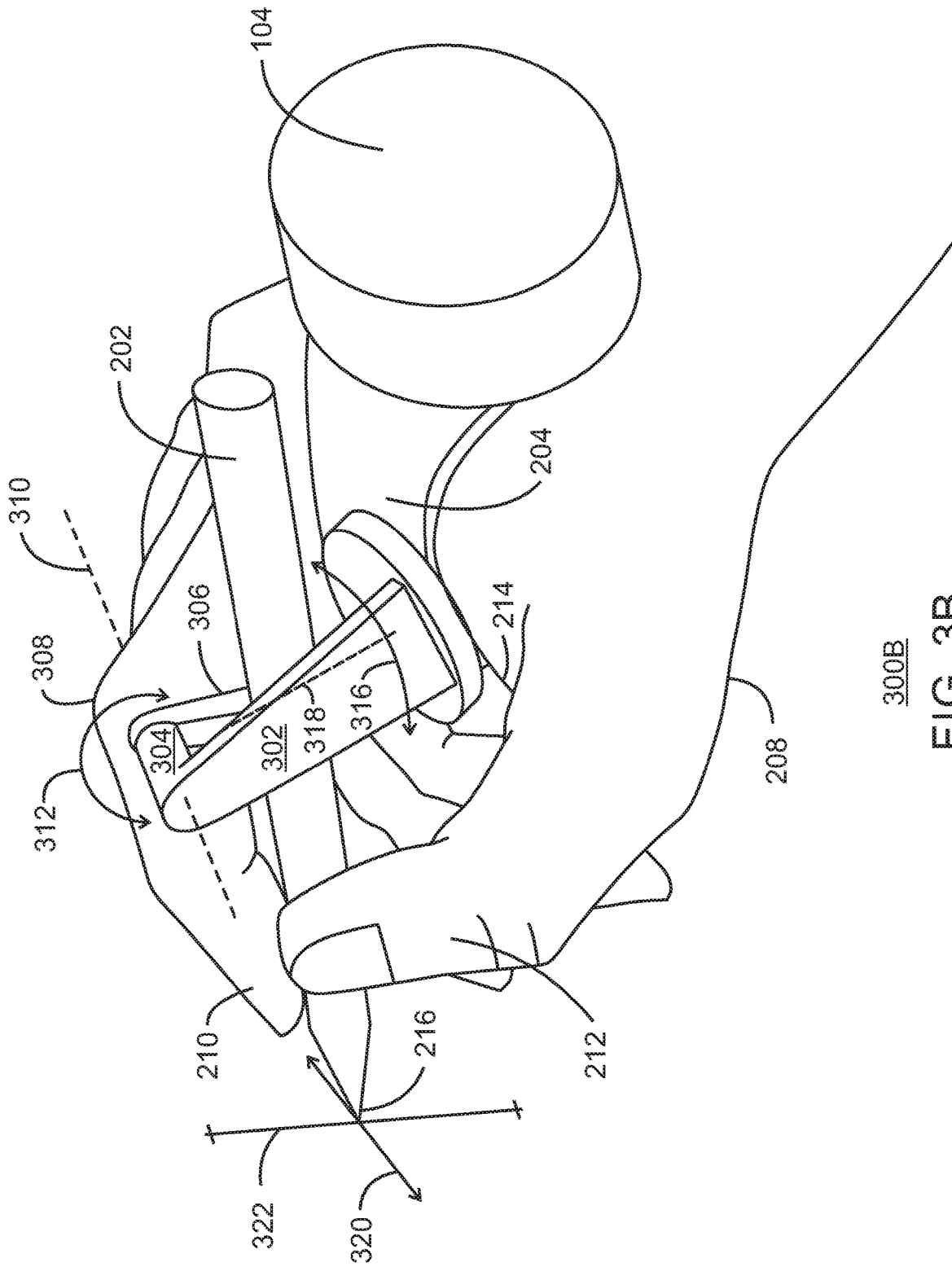
FIG. 1



200  
FIG. 2

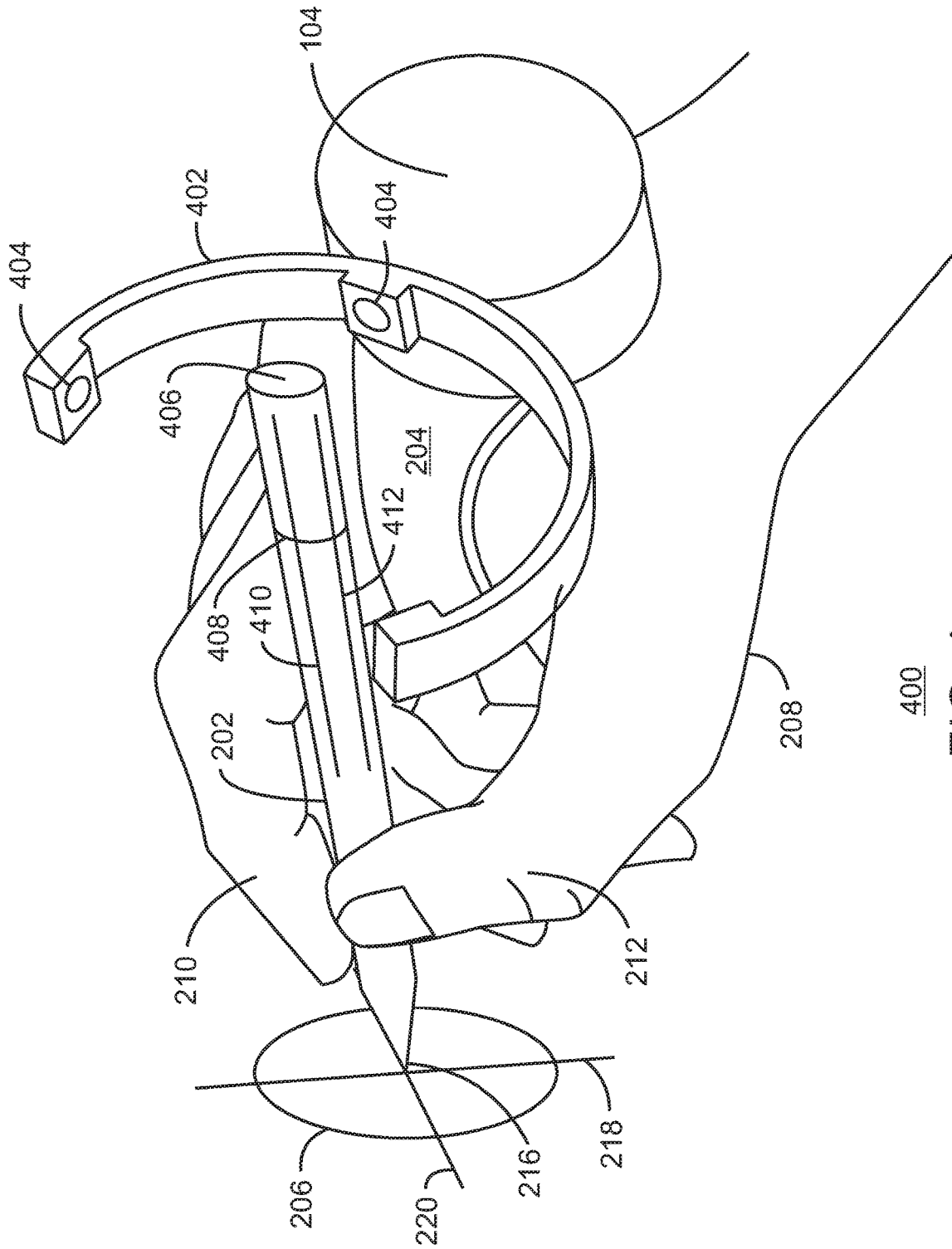


300A  
FIG. 3A

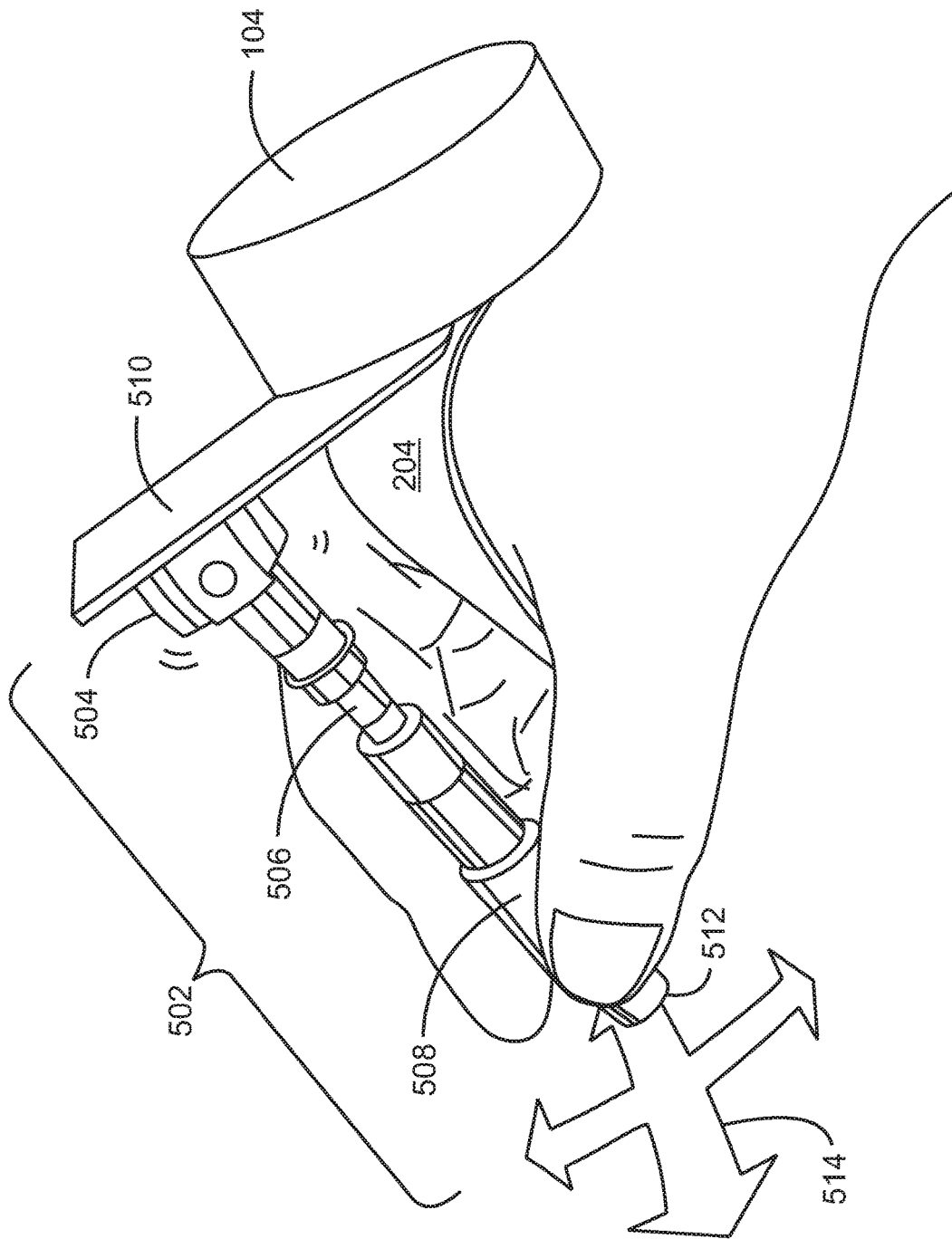


300B

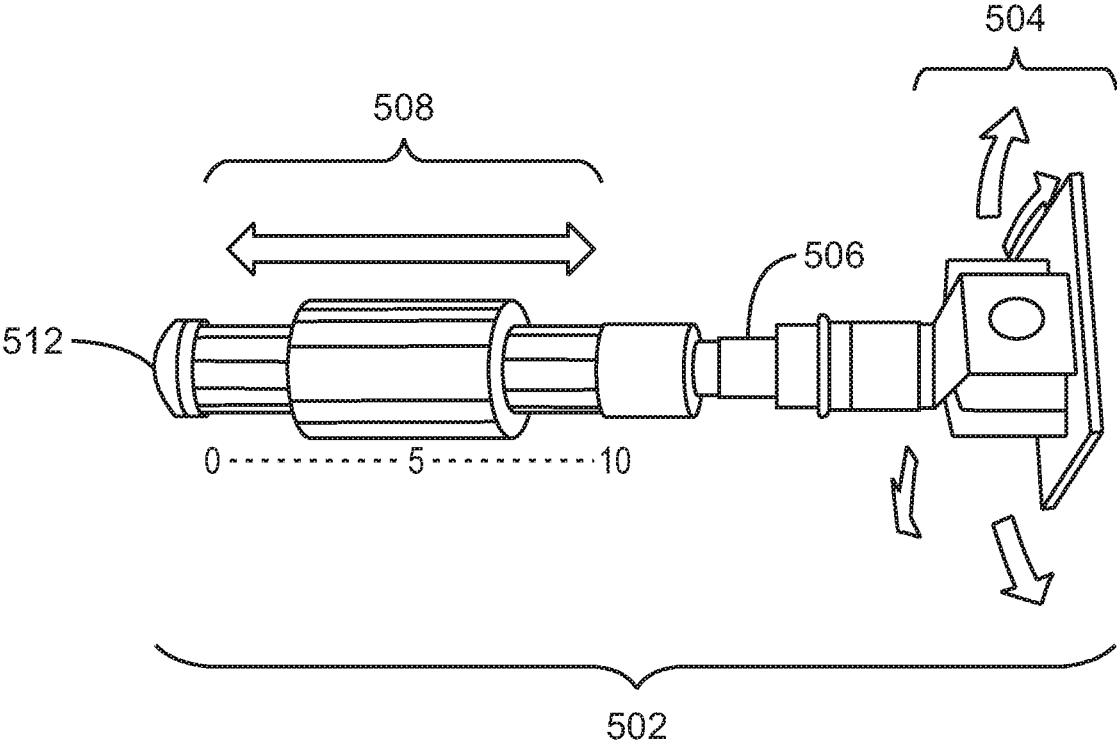
FIG. 3B



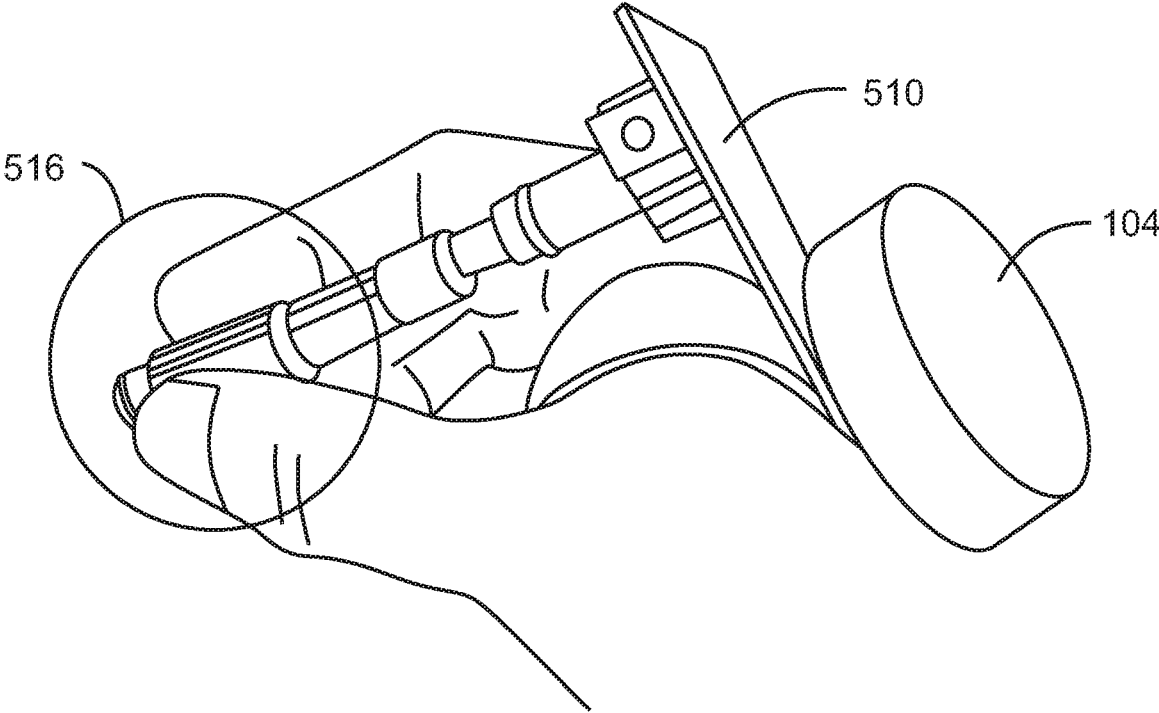
400  
FIG. 4



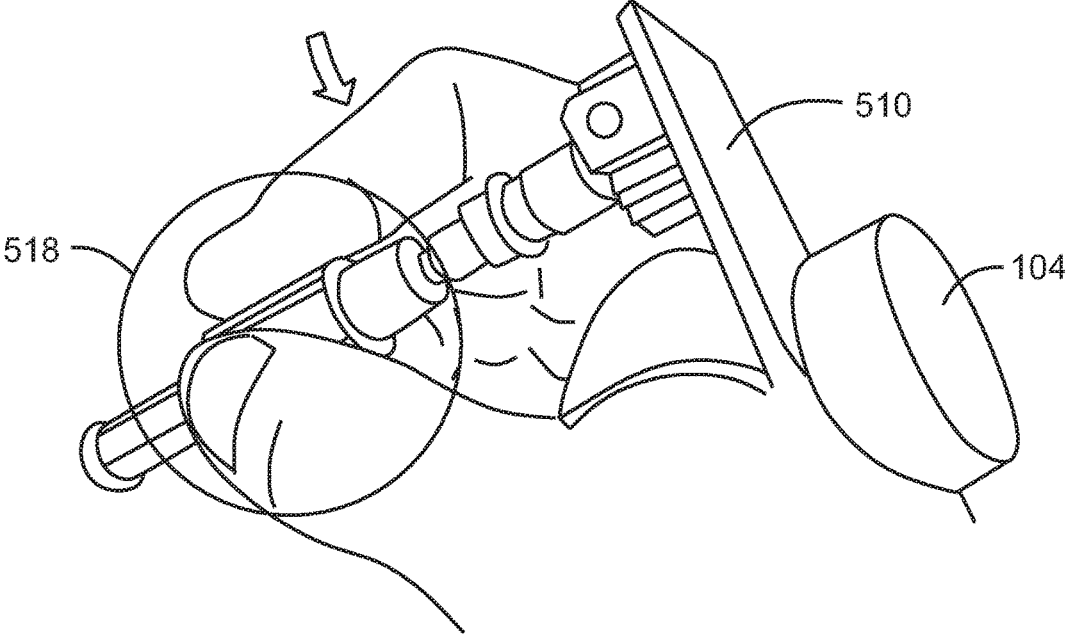
500A  
FIG. 5A



500B  
FIG. 5B

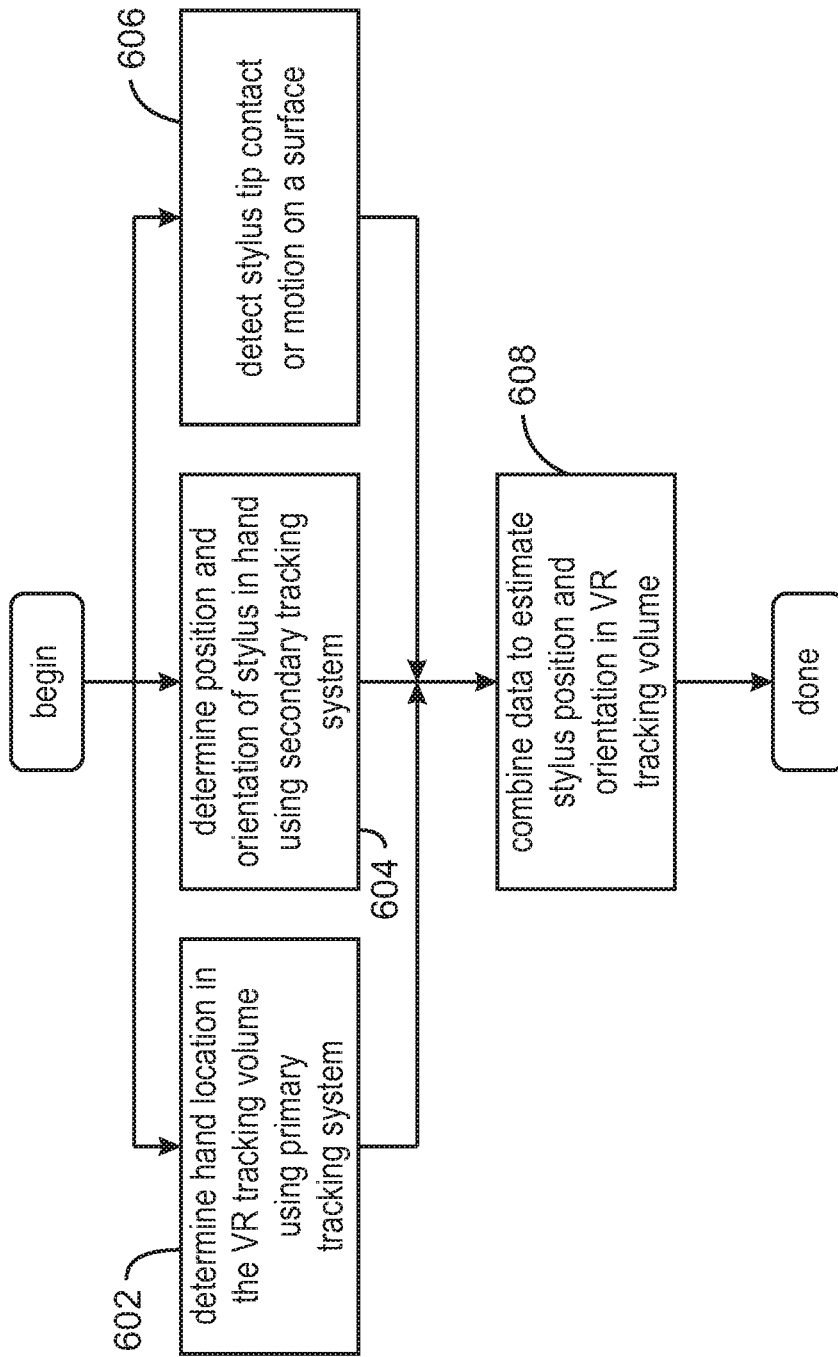


500C  
FIG. 5C



500D

FIG. 5D



600  
FIG. 6

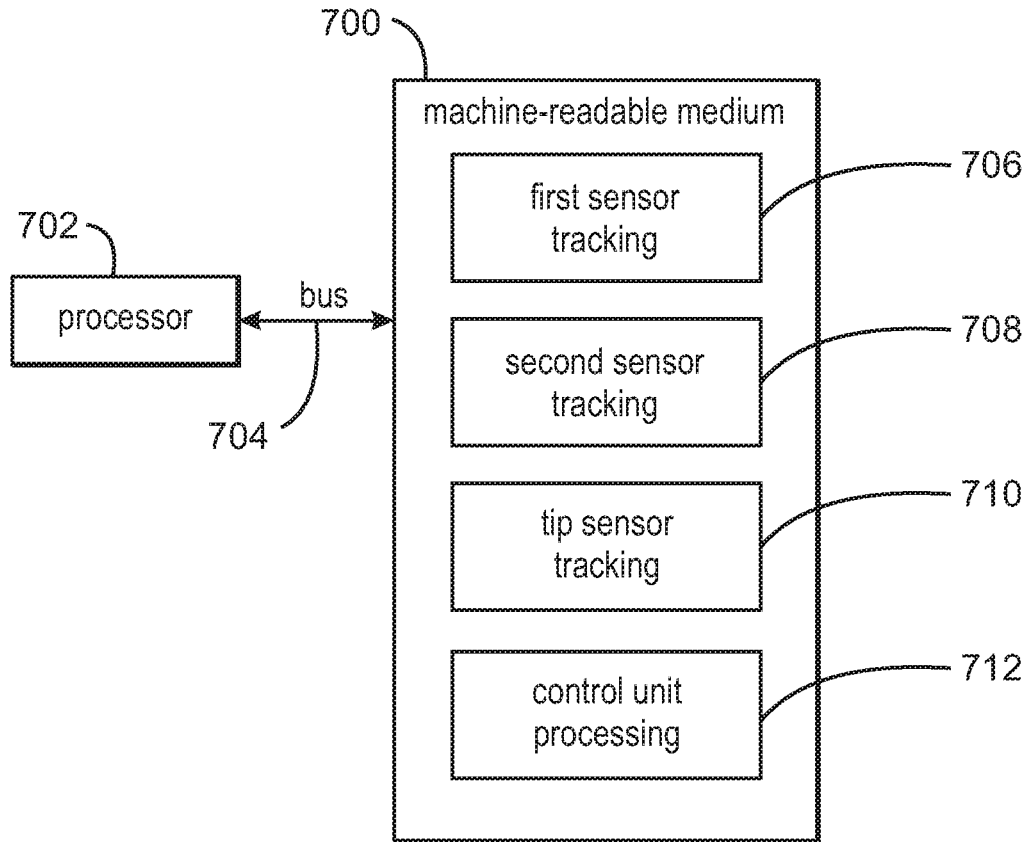


FIG. 7

## TRACKING STYLUS IN A VIRTUAL REALITY SYSTEM

### BACKGROUND

Many computer applications, of interest to workstations in particular (e.g., computer-aided design (CAD), media, and entertainment) rely on precision input. Current virtual reality (VR) or augmented reality (AR) controller technologies are not well-suited to capturing the precise motions of the human hand.

### BRIEF DESCRIPTION OF THE DRAWINGS

Certain examples are described in the following detailed description and in reference to the drawings, in which:

FIG. 1 is a schematic block diagram of a method of tracking a stylus in a virtual reality system, according to examples.

FIG. 2 is a diagram of an apparatus to implement the stylus tracking method of FIG. 1, according to examples.

FIGS. 3A and 3B are diagrams of a mechanical apparatus to implement the stylus tracking method of FIG. 1, according to examples.

FIG. 4 is a diagram of an optical apparatus to implement the stylus tracking method of FIG. 1, according to examples.

FIGS. 5A-5D are diagrams of a joystick apparatus to implement the stylus tracking method of FIG. 1, according to examples.

FIG. 6 is a flow diagram showing operation of the control unit from the stylus tracking method of FIG. 1, according to examples.

FIG. 7 is a block diagram of a non-transitory, machine-readable medium for performing the stylus tracking method of FIG. 1, according to examples.

The same numbers are used throughout the disclosure and the figures to reference like components and features. Numbers in the 100 series refer to features originally found in FIG. 1, numbers in the 200 series refer to features originally found in FIG. 2, and so on.

### DETAILED DESCRIPTION

In accordance with the examples described herein, a method and apparatus are disclosed to enable precise tracking of a hand-held stylus to be used in a virtual reality space. The apparatus consists of primary and secondary tracking systems. The primary tracking system, which monitors movement of a user's hand, includes a sensor that is attached to the user's hand. The secondary tracking system includes at least one additional sensor, with which position and orientation movement of the held stylus is monitored. Several example implementations are described. A tip sensor may additionally detect motion of the stylus over a surface and/or contact with the surface. Precise tracking of the stylus movement in a virtual reality setting, including the ability to discern letter writing on a surface or on air, is possible.

FIG. 1 is a schematic block diagram of a method of tracking a stylus 100, according to examples. The method 100 works with a stylus 102 that is used within a virtual reality (VR) tracking volume 118. A stylus is a pen-shaped device typically used to input commands to a computer screen, mobile device, or graphics tablet. As used herein, the VR tracking volume 118 comprises a physical space of a certain volume in which a user, with the help of a VR peripheral such as a headset, engages with the VR environment that is visible to the user. This volume is typically

constrained by the range limits of the sensors tracking the user's headset and other VR peripherals, such as hand controllers, and/or by physical obstacles in the space, such as walls and furniture. In contrast to typical stylus applications (computer, mobile, or tablet input device), the stylus 102 provides as input, the location of its tip, to a virtual reality system 116. The system may be a processor with an attached headset, or a self-contained VR headset.

The stylus 102 is to be placed in the hand of a user and held much like a pen or pencil. The stylus 102 is coupled to both a first tracking system 106 and a second tracking system 112. The first tracking system 106 monitors gross (large) movement of the stylus 102 within the VR tracking volume 118 and may also be referred to herein as the gross tracking system. Movement of the hand holding the stylus 102 is tracked by a sensor 104 of the gross tracking system 106. The second tracking system 112 monitors fine (small) movement of the stylus 102 within the VR tracking volume 118 and may also be referred to herein as the fine tracking system. Movement of a tip of the stylus 102 is monitored or tracked by a sensor 108 of the fine tracking system 112. A dashed arrow disposed between the first and second tracking systems indicates that the two tracking mechanisms may optionally be physically connected to one another.

A control unit or mechanism 114 receives information from both the first tracking system 106 and the second tracking system 112. Based on the sensory data received, the control unit 114 sends information 120 to a VR device 116. In an example, the information 120 is a precise location of the tip of the stylus within the VR tracking volume 118. The VR device 116 may be a headset or other VR peripheral worn by the user holding the stylus 102. The stylus-to-tracking systems information may be relayed separately to the control unit 114, or combined in the hand-worn device to provide a single set of 6DOF coordinates.

In some examples, the method 100 enables precision tracking of the stylus 102 by combining a hand-worn VR tracker (first tracking system 106) with one or more dedicated tracking sensors (second tracking system 112) between the hand-worn tracker and the stylus being manipulated by the user's fingers. The method 100 thus provides precise, pen-based input anywhere within the VR tracking volume.

Current six degrees of freedom (6DoF) tracking systems for VR peripherals may be accurate down to a few millimeters and a few degrees. These VR tracking systems tend to be large, as compared to a conventional stylus, due to the physical sensor separations used to optically triangulate the position of the VR peripheral. Current VR tracking systems are thus unsuitable to use with a stylus, for example, as these systems are unable to track fine motions of the stylus tip, such as when the user moves the stylus along a surface, or in the air, to "write" a letter or number.

Returning to FIG. 1, the first tracking system 106 emulates the tracking capability of current VR systems, in one example, to monitor movement of the user's hand. The second tracking system 112, by contrast, monitors the stylus motion with respect to the user's hand.

The second tracking system 112 optionally includes a tip sensor 110 disposed upon the tip of the stylus 102. The tip sensor 110 is used to increase the accuracy with which the stylus tip is tracked using the first sensor 108, in one example. Thus, the first sensor 108 and the tip sensor 110 work together to track the stylus 102. Further, the sensor 108 may actually comprise more than one sensor.

The control unit 114 receives sensor data from both the first tracking system 106 and the second tracking system 112. The control unit 114 may be a processor-based system

executing software to process the data, as one example. Or, the control unit **114** may be implemented using discrete logic (hardware). Or, the control unit **114** may utilize both hardware and software components to process the incoming data. Once the data has been processed by the control unit **114**, a tip location **120** is sent to the VR system **116**.

In the following pages, several example implementations of the stylus tracking method **100** are described in detail. The illustrations depict a right-handed user holding a stylus, but the examples described herein may also be implemented for left-handed users.

FIG. 2 is a diagram of an apparatus **200** to implement the stylus tracking method **100** of FIG. 1, according to examples. A stylus **202** is shown in a hand **208** of a user. Like a pen or pencil, the stylus **202** is disposed between the thumb **212** and index finger **210** of the hand **208**.

The sensor **104** of the first tracking system **106** is shown atop a palm **214** of the hand **208**. In FIG. 2, sensor **104** is coupled to a sleeve **204** connects to a bottom portion of the sensor and wraps around the palm **214**, leaving the hand **208** free to move the stylus **202**. The sleeve **204** may comprise a closed loop, such as of a stretchable fabric, where the user slides four fingers including the index finger **210** through the sleeve until the sensor **204** rests on the palm **214**. The sleeve **204** may “clip” over the base of the user’s thumb **212** as shown, allowing it be more readily picked up and put down (vs a glove). In another example, the sleeve is replaced with a glove (not shown). The sensor **104** tracks the motion of the palm **214**, in one example.

The stylus **202** includes a tip or nub **216**. A typical computer stylus, for example, would engage the tip of the stylus with a surface, such as a computer screen or tablet, which would invoke a response. For example, where the stylus tip engages with a “select” button on a tablet, a select operation would follow. In the world of VR, a stylus tip may engage with an actual physical surface. Or, the stylus tip may engage with a virtual surface, which is not an actual physical surface, where the virtual surface is visible to a user wearing a VR headset, for example. The principles of the stylus tracking method **100** described herein are capable of tracking the stylus tip, whether the tip engages with a surface or not.

An approximate range of motion **206** of the stylus tip **216** on a surface, with respect to the user’s hand **208**, is indicated in FIG. 2. Even when the hand **208** does not move, the movement of the stylus tip **216** may be made by movement of the index finger **210** and thumb **212**. A movement of the index finger **210** up or down, for example, may produce the vertical line **218** while coordinated movement of the index finger **210** and thumb **212** may produce the horizontal line **220**. In some cases, the hand **208** may be moved while the user is writing.

Thus, with the user’s hand **208** being stationary, the user can still manipulate the tip **216** of the stylus **202** with the index finger **210** and thumb **212** over roughly a square inch of surface area with sub-millimeter precision using finger motion, in one example.

FIGS. 3A and 3B are diagrams of a mechanical apparatus **300** to implement the stylus tracking method **100** of FIG. 1, according to examples. The mechanical apparatus **300** is illustrated in two parts, as apparatus **300A** (FIG. 3A) and as apparatus **300B** (FIG. 3B), respectively (collectively, “apparatus **300**”). The first tracking system of the mechanical apparatus **300** is the sensor **104** coupled to the hand **208** by the sleeve **204**, as before. The second tracking system of the mechanical apparatus **300** comprises a mechanical linkage capturing the position of the stylus **202**, and thus the stylus

tip **216**. While a freely moving stylus may typically be moved within a roughly elliptical area by the user’s fingers when the hand is held stationary, a larger component of that motion is governed by rotation about the first joint of the user’s index finger. Capturing that motion captures the bulk of the typical pen motion with respect to the hand.

Thus, in FIG. 3A, the mechanical linkage of the apparatus **300** comprises a projection **302** coupled to the sleeve **204**, a cylinder **304** orthogonal to the projection, and a connection **306** to the stylus **202**. The projection **302** projects upward from the palm **214** of the hand **208** and is disposed to the left of the stylus **202**. Connected to the projection, the cylinder **304** is disposed to the left of a knuckle **308** of the index finger **210**. In an example, the cylinder **304** is roughly co-axial with the knuckle **308**, with the dotted line **310** indicating the axis shared by the knuckle and cylinder. The connection **306** is fixably attached to the stylus **202**, in one example, and is approximately parallel to the projection **302**. In one example, the pivot **304** comprises a rotational encoder (not shown). When the pivot **304** rotates, as indicated by the arrow **312**, the rotational encoder tracks up and down movement **308** of the stylus tip **216** and sends the information to the control unit **114** (FIG. 1). The ability to track a simple up-and-down motion of the stylus **202** may be sufficient for some applications.

In FIG. 3B, however, the mechanical apparatus **300B** further includes means to track the left and right motion of the stylus **202**, according to examples. In addition to the components shown in FIG. 3A, the mechanical apparatus **300B** includes the projection **302** coupled to the cylinder **304** at one end, and to a disc **314** at its other end. Like the pivot **304**, the disc **314** may include a rotational encoder (not shown), in this case, to track the left and right motion of the stylus **202**. When the stylus **202** moves left to right or right to left, such as along the line **320**, the disc **314** moves as indicated by the arrow **316**. The mechanical apparatus **300B** thus tracks both up-and-down motion and left-and-right motion of the stylus.

FIG. 4 is a diagram of an optical apparatus **400** to implement the stylus tracking method **100** of FIG. 1, according to examples. The first tracking system of the optical apparatus **400** is the sensor **104** coupled to the hand **208** by the sleeve **204**, as before. The second tracking system of the optical apparatus **400** comprises an attachment **402** comprising cameras **404** to capture the position of the stylus **202**, and thus the stylus tip **216**.

The attachment **402** is coupled to the hand sensor **104** and partially surrounds an end portion **406** of the stylus **202** that is opposite to the tip **216**. In the illustration of FIG. 4, the attachment **402** is shaped like a partial slice of a cylinder and is disposed so as to partially surround the end **406** of the stylus **202**. In examples, in an initial state, the attachment **402** is positioned such that the cameras **404** are approximately equidistant from the end **406** of the stylus **202**.

In the optical apparatus **400**, although the attachment **402** is coupled to the sensor **104** of the first tracking system, the stylus **202** is free to move with respect to the hand-worn portion. The attachment **402** is designed so as to not interfere with the range of motion of the stylus **202**. In one example, the attachment **402** includes two or more cameras **404** that encircle the volume typically occupied by the top end **406** of the stylus **202**. Fiducials **408**, **410**, and **412** on the stylus **202** simplify the task of identifying the position and orientation of the stylus in each camera’s image. The fiducial **408** is shown wrapping around the stylus **102** near the end **406** while the fiducials **410** and **412** are disposed along the shaft of the stylus and orthogonal to the fiducial **408**. Other

arrangements of fiducial positions are possible. The cameras **404** measures changes in the fiducials, and this information is sent to the control unit **114** (FIG. 1). These measurements are combined to create an estimate of the tip position **216** with respect to the hand-worn tracker **204**.

FIGS. 5A-5D are diagrams of a joystick apparatus **500A-500D** (collectively, “joystick apparatus **500**”) to implement the stylus tracking method **100** of FIG. 1, according to examples. The first tracking system of the joystick apparatus **500** is the sensor **104** coupled to the hand **208** by the sleeve **204**, as before. The second tracking system of the joystick apparatus **500** comprises a stylus **502** with both a joystick sensor **504** and a z-axis sensor **508**. Together, these sensors are able to discern fine movement of the stylus **502**, in some examples.

As shown in FIG. 5A, the stylus **502** of the joystick apparatus **500** comprises the joystick sensor **504** at one end, a shaft **506**, the z-axis sensor **508**, and a tip **510**. In an example, the joystick sensor **504** detects changes in x-y angles when the user writes characters using the stylus **502**. As with the mechanical apparatus **300** and the optical apparatus **400**, the user does not need a writing surface to write characters with the stylus of the joystick apparatus **500**.

In the joystick apparatus **500**, the grip position of the stylus **502** is tracked via the z-axis sensor **508**, in one example. For example, when the user is writing big letters, the user’s grip on the stylus is a greater distance away from the tip, compared to when the user is writing small letters. Data from the z-axis sensor **508** may be combined with data from the joystick sensor **504** to accurately simulate the user’s writing intent. Data retrieved by the z-axis sensor **508** and the joystick sensor **504** are sent to the control unit **114** (FIG. 1). In the illustration **500A**, the stylus **502** is coupled to an attachment **510**, which is itself coupled to the sensor **104** and sleeve **204**. In an example, the attachment **510** enables an electrical connection, such as by copper wires, between the sensor **104** and the joystick sensor **504**.

FIG. 5B shows the joystick apparatus **500B** free of the user’s hand. With the stylus **502** positioned horizontally, the joystick sensor **504**, disposed at the end opposite the tip **512**, is able to detect movement of the stylus **502** in a number of different directions, such as upward, downward, left-to-right, and right-to-left. The z-axis sensor **508**, a cylindrical sleeve disposed along the shaft **506** of the stylus **502**, instead detects up and down movement along the shaft. The z-axis sensor **508** may move all the way down the shaft **506** toward the tip **512**, or up the shaft toward the joystick sensor **504**.

A legend beneath the z-axis sensor **508** in the illustration **500B** indicates its position. The illustration **500C** in FIG. 5C show the z-axis sensor **508** in the “0” position, or close to the tip **512**. The illustration **500D** in FIG. 5D shows the z-axis sensor **508** in the “10” position, which is farthest away from the tip **512**.

Returning to FIG. 1, the first tracking system **106** works with the second tracking system **112** to determine the tip location **120** to be sent to the VR device **116**. Thus, the sensor **104**, which provides a first location of the user, is combined with the sensor or sensors, which provide the second location of the stylus. In examples, the second location is given in relation to the first location.

In some examples, the mechanical apparatus **300**, the optical apparatus **400**, and the joystick apparatus **500** may additionally include a sensor disposed on the stylus tip (e.g., tip sensor **110** in FIG. 1). In conjunction with the one or more other sensors of the second tracking system **112**, the tip sensor may be used to increase the accuracy with which the

stylus tip is tracked. For instance, the tip sensor **110** may be implemented as a contact sensor, which will determine when the stylus is being used on a surface. If the surface is assumed to be horizontal, then the stylus tracking method **100** has a useful constraint for calculation of the position of the tip. If the tip sensor **110** incorporates a mouse-like two-dimensional motion tracker, such as an optical mouse sensor, then that detailed delta-X, delta-Y tracking information may be fused with the information from the sensor **104** of the first tracking system **106** and the sensor(s) **108** of the second tracking system **112** to improve the accuracy of the estimation of the tip motion of the stylus.

The hand worn device may just “clip” over the base of the user’s thumb as shown, allowing it be more readily picked up and put down (vs a glove).

Using either the mechanical apparatus **300**, the optical apparatus **400**, or the joystick apparatus **500**, the stylus tracking method **100** enables the user to write “in the air” or on any available surface, in some examples. The stylus tracking method **100** thus combines pen movement sensing technology in the above-mentioned combinations with large spatial tracking applications.

The method **100** may have applications outside of AR/VR. Many computer applications may use input via a stylus. The method **100** and apparatus **300**, **400**, and **500** give the user the ability to use a stylus, not just on a digitizing surface, such as a tablet screen, but in a number of different applications in which precise motions of the stylus tip are desired.

FIG. 6 is a flow diagram **600** illustrating operations that may be performed by the control unit **114** to determine the tip location **120** (FIG. 1), according to examples. The location of the user’s hand is determined in the VR tracking volume by the primary tracking system (block **602**). The position and orientation of the stylus, specifically, the tip of the stylus, is determined by the secondary tracking system (block **604**). Where the optional tip sensor is available, the stylus tip contact or motion on a surface is detected (block **606**). The information from the primary tracking system, the secondary tracking system, and the optional tip sensor are combined in the control unit to estimate the stylus position and orientation in the VR tracking volume (block **608**). The operations **602**, **604**, and **606** are shown being performed together. However, these operations may be performed together or in succession, in any order.

FIG. 7 is a block diagram of a non-transitory, machine-readable medium for performing the stylus tracking method of FIG. 1, according to examples. A processor **702** may access the non-transitory, machine readable medium over a reader mechanism, as indicated by arrow **704**.

The non-transitory, machine readable medium **700** may include code, specifically modules **706**, **708**, **710**, and **712**, to direct the processor **702** to implement operations for performing the stylus tracking method. First sensor tracking **706** determines the position of the hand holding the stylus, as described above. Second sensor tracking **708** determines the position of the stylus using one or more sensors, as described above. Optional tip sensor tracking **710** helps determine the position of the stylus tip when in contact with a surface. Control unit processing **712** gathers the data from the first sensor tracking **706**, the second sensor tracking **708**, and the tip sensor tracking **710**, to supply the tip location to a VR device.

While the present techniques may be susceptible to various modifications and alternative forms, the techniques discussed above have been shown by way of example. It is to be understood that the technique is not intended to be

limited to the particular examples disclosed herein. Indeed, the present techniques include all alternatives, modifications, and equivalents falling within the scope of the following claims.

What is claimed is:

1. An apparatus comprising:
  - a primary tracking system comprising a first sensor to monitor first movement of a user's hand, wherein the first sensor is attached to the user's hand; and
  - a secondary tracking system to monitor second movement of an object held in the user's hand and a position of the object, the secondary tracking system comprising at least one additional sensor, a pivot disposed coaxial with a knuckle of an index finger of the user's hand, and a rotational encoder to measure rotation of the pivot; wherein the position is measured in relation to the first movement.
2. The apparatus of claim 1, wherein the secondary tracking system further detects an orientation of the object.
3. The apparatus of claim 1, wherein the secondary tracking system further comprises a second sensor to detect the object movement in a two-dimensional plane.
4. The apparatus of claim 3, wherein the secondary tracking system further comprises a third sensor to detect the object movement in a direction orthogonal to the two-dimensional plane.
5. The apparatus of claim 1, wherein rotation of the pivot indicates up and down movement of the index finger.
6. The apparatus of claim 5, the secondary tracking system further comprising:
  - a second pivot disposed orthogonal to the pivot; and
  - a second rotational encoder to measure rotation of the second pivot;
 wherein rotation of the second pivot indicates side-to-side movement of the index finger.
7. The apparatus of claim 1, the secondary tracking system further comprising:
  - a joystick sensor disposed at one end of the object, wherein the joystick sensor is coupled to the first sensor; and
  - a z-position sensor disposed along a shaft of the object.
8. An apparatus comprising:
  - a primary tracking system comprising a first sensor to monitor first movement of an object in a user's hand; and

- a secondary tracking system comprising:
  - a second sensor to detect a position and orientation of the object within a working volume adjacent to the second sensor;
  - a structure partially encircling a top portion of the object, wherein the structure is equidistant from the top portion; and
  - a plurality of cameras affixed to the structure such that the top portion of the object is in view of each of the plurality of cameras;
 wherein the position and orientation are measured in relation to the first movement.
- 9. The apparatus of claim 8, wherein a plurality of fiducials is disposed around the top portion of the object; wherein the plurality of cameras tracks rotational movement of the object by observing movement of one or more of the plurality of fiducials.
- 10. The apparatus of claim 8, wherein the structure is affixed to the first sensor.
- 11. A method to track movement of a tip of a stylus in a human hand, the method comprising:
  - monitoring a first movement of the human hand by coupling a first sensor over a palm of the human hand;
  - monitoring a first stylus movement using a second sensor; and
  - monitoring a second stylus movement using a third sensor, wherein the second stylus movement is orthogonal to the first stylus movement;
 wherein the first and second stylus movements are measured relative to the first movement of the human hand.
- 12. The method of claim 11, further comprising a controller to receive:
  - the first movement of the human hand from the first sensor;
  - the first stylus movement from the second sensor; and
  - the second stylus movement from the third sensor;
 wherein the controller processes the first movement, then derives the first and second stylus movements based on the first movement.
- 13. The method of claim 12, further comprising coupling the first sensor to the second sensor.
- 14. The method of claim 11, further comprising:
  - a tip sensor disposed on the tip of the stylus, the tip sensor to detect contact with a surface or motion of the tip over a surface.

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